

ABSTRACT OF THE DISCLOSURE

[00102] A method and apparatus for determining camera pose from point correspondences. Specifically, an efficient solution to the classical five-point relative pose problem is presented. The problem is to find the possible solutions for relative camera motion between two calibrated views given five corresponding points. The method consists of computing the coefficients of a tenth degree polynomial and subsequently finding its roots. The method is well suited for numerical implementation that also corresponds to the inherent complexity of the problem. The method is used in a robust hypothesize- and-test framework to estimate structure and motion in real-time.